

IN THE SUBSTITUTE SPECIFICATION:

Pages 1 and 2,                   amend paragraph [0002] starting on page 1 at line 7 and ending on page 2 at line 9 as follows:

[0002] The present invention pertains to a welding torch device of a welding robot, which is provided for electric arc welding, and in particular MIG ~~f~~(metal inert gas=~~Tr.~~) or MAG ~~f~~(metal active gas=~~Tr.~~) welding. Such a welding robot usually has a robot arm, on which is provided a connection flange that can be rotated in relation to the robot. The welding torch device comprises a fixing device for attaching the welding torch device to the welding robot as well as a receiving device for receiving a welding torch and transferring a preferably motor-driven rotatory motion to the welding torch. By means of a connection for a welding power cable, a robot side of the welding torch device can be electrically connected to a welding power source. The welding torch device also comprises a current transfer device, via which the welding power cable can be electrically connected to a welding torch side of the welding torch device, whereby the current transfer device has a stator that is provided for the rotationally fixed arrangement in relation to the robot arm, but can be rotated in relation to the connection flange of the welding robot. In this case, the stator shall be provided with a leadthrough, through which at least one of the welding media required for the welding process can be guided in the direction of the receiving device.

Page 9,                   amend paragraph [0029] starting at line 7 and ending at line 13 as follows:

[0029] Referring to the drawings in particular, ~~The~~ the folding arm robot 1 shown in Figures

1, 7 and 8 is a commercially available robot, as it is often used. For example, the robots of the EA series, which are offered by the company Motoman rototec GmbH, 85391 Allershausen, are suitable in conjunction with the present invention. The robot has a frame part 2 and an arm 3 arranged thereon, which is provided with a plurality of joints 4. The free end 5 of the arm of the folding arm robot is consequently capable of traveling the entire length of any three-dimensionally running paths of motion.